

Altruistic and Aggressive Types of Behavior in a Non-Antagonistic Positional Differential Two-Person Game

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Abstract: A non-antagonistic positional differential two-person game is considered in which each of the two players, in addition to the usual normal (*nor*) type of behavior oriented toward maximizing own functional, can use other types of behavior. In particular, it is altruistic (*alt*), aggressive (*agg*) and paradoxical (*par*) types. It is assumed that in the course of the game players can switch their behavior from one type to another. In this game, each player along with the choice of positional strategy also chooses the indicator function defined over the whole time interval of the game and taking values in the set $\{nor, alt, agg, par\}$. Player's indicator function shows the dynamics for changing the type of behavior that this player adheres to. The concept of *BT*-solution for such game is introduced. Using players types of behavior other than normal, can lead to outcomes more preferable to them than in a game with only a normal type of behavior. An example of a game with the dynamics of simple motion in the plane and phase constraints illustrates the procedure for constructing *BT*-solutions.

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1. INTRODUCTION

In the present paper we consider a non-antagonistic positional differential two-person game (see, for example, Basar and Olsder [1999], Petrosyan and Zenkevich [2012]), for which emphasis is placed on the case where each of the two players, in addition to the normal (*nor*), type of behavior oriented on maximizing their own functional, can use other types of behavior introduced in Kleimenov [1997], Kleimenov and Kryazhinskii [1998], such as altruistic (*alt*), aggressive (*agg*) and paradoxical (*par*) types. It is assumed that during the game, players can switch their behavior from one type to another. The idea of using the players to switch their behavior from one type to another in the course of the game was applied to the game with cooperative dynamics in Kleimenov and Kryazhinskii [1998] and for the repeated bimatrix 2×2 game in Kleimenov [1999], which allowed to obtain new solutions in these games. It is also assumed that in the game each player chooses the indicator function determined over the whole time interval of the game and takes values in the set $\{nor, alt, agg, par\}$, along with the choice of the positional strategy. Player's indicator function shows the dynamics for changing the type of behavior that this player adheres to. Rules for the formation of controls are introduced for each pair of behaviors of players.

The formalization of positional strategies in the game is based on the formalization and results of the general theory of antagonistic positional differential games Krasovskii and Subbotin [1988], Krasovskii [1985]. For non-antagonistic differential games this formalization was developed in Kleimenov [1993].

In the paper the concept of the *BT*-solution is introduced.

An example of a game with dynamics of simple motion in the plane and phase constraints in two variants is proposed. In the first variant we assume that the first and second players can exhibit altruism towards their partner for some time periods. In the second variant, in addition to the assumption of altruism of the players, we also assume that each player can act aggressively against another player for some periods of time, and a case of mutual aggression is allowed. In both variants sets of *BT*-solutions are described. This paper is a continuation of Kleimenov [1999], Kleimenov [2015], Kleimenov [2017].

The paper is organized as follows. Section 2 contains some results from the theory of non-antagonistic positional differential games. Definitions of various types of behavior for players are given in Section 3. The concept of the *BT*-solution is introduced. Section 4 contains an example of the game with dynamics of simple motions and with phase constraints.

2. SOME RESULTS FROM THE THEORY OF NON-ANTAGONISTIC POSITIONAL DIFFERENTIAL GAMES

2.1 Dynamics of the game.

Consider a two-person non-antagonistic positional differential game (NPDG) which dynamics is described by the following equation

$$\dot{x} = f(t, x, u, v), \quad t \in [t_0, \vartheta], \quad x(t_0) = x_0 \quad (1)$$

where $x \in R^n$ is a phase vector; the controls $u \in P \in \text{comp}R^p$ and $v \in Q \in \text{comp}R^q$ are handled by Player 1 (P1) and Player 2 (P2), respectively.

Let G be a compact set in $R^1 \times R^n$ whose projection on the time axis is equal to the given interval $[t_0, \vartheta]$. We assume, that all the trajectories of system (1), beginning at an arbitrary position $(t_*, x_*) \in G$, remain within G for all $t \in [t_*, \vartheta]$.

Let the following assumptions be fulfilled.

1⁰. The function $f : G \times P \times Q \mapsto R^n$ is continuous over the set of arguments.

2⁰. The function f satisfies the Lipschitz condition with respect to x .

3⁰. There exists a constant $\lambda > 0$ such that

$$\|f(t, x, u, v)\| \leq \lambda(1 + \|x\|)$$

for all $(t, x) \in G$, $u \in P$, $v \in Q$.

4⁰. The function $f(t, x, u, v)$ satisfies the condition

$$\max_{u \in P} \min_{v \in Q} s^T f(t, x, u, v) = \min_{v \in Q} \max_{u \in P} s^T f(t, x, u, v)$$

for any $s \in R^n$ and $(t, x) \in G$. Here and below the upper symbol T denotes the operation of transposition.

2.2 Formalization of strategies and motions.

Assume that both players have information about the current position of the game $(t, x(t))$. Then P1 and P2 acts in the class of pure positional strategies.

The formalization of players' positional strategies and motions generated by them in a NPDG is based on the formalization and results of antagonistic positional differential games theory from the books Krasovskii [1985], Krasovskii and Subbotin [1988]. The following presentation is given in Kleimenov [1993].

Strategy of P1 is identified with the pair $U = \{u(t, x, \varepsilon), \beta_1(\varepsilon)\}$, where $u(\cdot)$ is an arbitrary function of position (t, x) and a positive precision parameter $\varepsilon > 0$ and taking values in the set P . The function $\beta_1 : (0, \infty) \mapsto (0, \infty)$ is a continuous monotonic function satisfying the condition $\beta_1(\varepsilon) \rightarrow 0$ if $\varepsilon \rightarrow 0$. For a fixed ε the value $\beta_1(\varepsilon)$ is the upper bound step of subdivision the segment $[t_0, \vartheta]$, which P1 applies when forming step-by-step motions. Similarly, the strategy of P2 is defined as $V = \{v(t, x, \varepsilon), \beta_2(\varepsilon)\}$.

Motions of two types - approximated (step-by-step) and ideal (limiting) are considered as motions generated by a pair {strategy of P1 – strategy of P2}.

Approximated motion $x_\Delta^\varepsilon[\cdot] = x[\cdot, t_0, x_0, U, \varepsilon_1, \Delta_1, V, \varepsilon_2, \Delta_2]$ generated by a pair of strategies (U, V) from initial position (t_0, x_0) is introduced for fixed values of the players' precision parameters ε_1 and ε_2 and for fixed subdivisions $\Delta_1 = \{t_i^{(1)}\}$ and $\Delta_2 = \{t_j^{(2)}\}$ of the interval $[t_0, \vartheta]$ chosen by P1 and P2, respectively, under the conditions $\delta(\Delta_i) \leq \beta_i(\varepsilon_i), i = 1, 2$ as step-by-step solution of the differential equation

$$\begin{aligned} \dot{x}_\Delta^\varepsilon[t] &= f(t, x_\Delta^\varepsilon[t], u_{\Delta_1}^{\varepsilon_1}[t], v_{\Delta_2}^{\varepsilon_2}[t]), \quad x_\Delta^\varepsilon[t_0] = x_0, \\ u_{\Delta_1}^{\varepsilon_1}[t] &= u(t_i^{(1)}, x_\Delta^\varepsilon[t_i^{(1)}], \varepsilon_1), \quad t_i^{(1)} \leq t < t_{i+1}^{(1)}, \\ v_{\Delta_2}^{\varepsilon_2}[t] &= v(t_j^{(2)}, x_\Delta^\varepsilon[t_j^{(2)}], \varepsilon_2), \quad t_j^{(2)} \leq t < t_{j+1}^{(2)}. \end{aligned} \quad (2)$$

A limiting motion generated by the pair of strategies (U, V) from initial position (t_0, x_0) is a continuous function

$x[t] = x[t, t_0, x_0, U, V]$ for which there exists a sequence of approximated motions $\{x[t, t_0^k, x_0^k, U, \varepsilon_1^k, \Delta_1^k, V, \varepsilon_2^k, \Delta_2^k]\}$, uniformly converging to $x(t)$ on $[t_0, \vartheta]$ as $k \rightarrow \infty$, $\varepsilon_1^k \rightarrow 0$, $\varepsilon_2^k \rightarrow 0$, $t_0^k \rightarrow t_0$, $x_0^k \rightarrow x_0$.

A pair of strategies (U, V) generates a nonempty compact (in the metric of the space $C[t_0, \vartheta]$) set $X(t_0, x_0, U, V)$ consisting of limit motions $x[\cdot, t_0, x_0, U, V]$.

The control laws $(U, \varepsilon_1, \Delta_1)$ and $(V, \varepsilon_2, \Delta_2)$ are said to be agreed with respect to the precision parameter if $\varepsilon_1 = \varepsilon_2$. Agreed control laws generate agreed approximate motions, the sequences of which generate agreed limit motions.

2.3 Players' payoff functionals

Player i chooses his control to maximize the payoff functional

$$I_i = \sigma_i(x[\vartheta]), \quad i = 1, 2 \quad (3)$$

where $\sigma_i : R^n \mapsto R^1$ are given continuous functions.

2.4 NE- and P(NE) -solutions in NPDG.

We introduce the following definitions from Kleimenov [1993].

Definition 1. A pair of strategies (\tilde{U}, \tilde{V}) is called a Nash equilibrium solution (NE-solution) of the game, if for any motion $x^*[\cdot] \in X(t_0, x_0, \tilde{U}, \tilde{V})$, any moment $\tau \in [t_0, \vartheta]$, and any strategies U and V the following inequalities hold

$$\begin{aligned} \max_{x[\cdot]} \sigma_1(x[\vartheta, \tau, x^*[\tau], U, \tilde{V}]) &\leq \min_{x[\cdot]} \sigma_1(x[\vartheta, \tau, x^*[\tau], \tilde{U}, \tilde{V}]), \\ \max_{x[\cdot]} \sigma_2(x[\vartheta, \tau, x^*[\tau], \tilde{U}, V]) &\leq \min_{x[\cdot]} \sigma_2(x[\vartheta, \tau, x^*[\tau], \tilde{U}, \tilde{V}]). \end{aligned} \quad (4)$$

where the operations \min are performed over a set of agreed motions, and the operations \max by sets of all motions.

Definition 2. An NE-solution (U^P, V^P) which is Pareto non-improvable with respect to the values I_1, I_2 (3) is called a P(NE)-solution.

2.5 Auxiliary antagonistic positional differential games Γ_1 and Γ_2 .

Dynamics of both games is described by the equation (1). In the game Γ_i Player i maximizes the payoff functional $\sigma_i(x(\vartheta))$ (3) and Player $3-i$ opposes him. It follows from Krasovskii [1985], Krasovskii and Subbotin [1988] that both games Γ_1 and Γ_2 have universal saddle points

$$\{u^{(i)}(t, x, \varepsilon), \quad v^{(i)}(t, x, \varepsilon)\}, \quad i = 1, 2 \quad (5)$$

and continuous value functions

$$\gamma_1(t, x), \quad \gamma_2(t, x) \quad (6)$$

The property of strategies (5) to be universal means that they are optimal not only for the fixed initial position $(t_0, x_0) \in G$ but also for any position $(t_*, x_*) \in G$ assumed as initial one.

It is not difficult to see that the value of $\gamma_i(t, x)$ is the guaranteed payoff of the Player i in the position (t, x) of the game.

2.6 The structure of NE - and $P(NE)$ -solutions in NPDG

In Kleimenov [1993] the following structure of NE - and $P(NE)$ -solutions was established. Namely, it was shown that all NE - and $P(NE)$ -solutions of the game NPDG can be found in the class of pairs of strategies (U, V) each of which generates a unique limit motion (trajectory). The decision strategies that make up such a pair generating the trajectory $x^*(\cdot)$ have the form

$$U^0 = \{u^0(t, x, \varepsilon), \beta_1^0(\varepsilon)\}, V^0 = \{v^0(t, x, \varepsilon), \beta_2^0(\varepsilon)\}, \quad (7)$$

$$u^0(t, x, \varepsilon) = \begin{cases} u^*(t, \varepsilon), & \|x - x^*(t)\| < \varepsilon\varphi(t) \\ u^{(2)}(t, x, \varepsilon), & \|x - x^*(t)\| \geq \varepsilon\varphi(t) \end{cases}$$

$$v^0(t, x, \varepsilon) = \begin{cases} v^*(t, \varepsilon), & \|x - x^*(t)\| < \varepsilon\varphi(t) \\ v^{(1)}(t, x, \varepsilon), & \|x - x^*(t)\| \geq \varepsilon\varphi(t) \end{cases}$$

for all $t \in [t_0, \vartheta]$, $\varepsilon > 0$. In (7) we denote by $u^*(t, \varepsilon)$, $v^*(t, \varepsilon)$ families of program controls generating the limit motion $x^*(t)$. The function $\varphi(\cdot)$ and the functions $\beta_1^0(\cdot)$ and $\beta_2^0(\cdot)$ are chosen in such a way that the approximated motions generated by the pair (U^0, V^0) from the initial position (t_0, x_0) do not go beyond the $\varepsilon\varphi(t)$ -neighborhood of the trajectory $x^*(t)$. Functions $u^{(2)}(\cdot, \cdot, \cdot)$ and $v^{(1)}(\cdot, \cdot, \cdot)$ are defined in (5).

Further, for each NE - and $P(NE)$ -trajectories $x^*(t)$ the following property holds.

Property 1. The point $t = \vartheta$ is the maximum point of the value function $\gamma_i(t, x)$ (6) computed along this trajectory, that is,

$$\gamma_i(t, x^*(t)) \leq \gamma_i(\vartheta, x^*(\vartheta)), \quad t_0 \leq t \leq \vartheta, \quad i = 1, 2 \quad (8)$$

3. A NON-ANTAGONISTIC POSITIONAL DIFFERENTIAL GAMES WITH BEHAVIOR TYPES.

3.1 Behavior Types for Players

Now we assume that in addition to the usual normal (*nor*) type of behavior aimed at maximizing own functionals (3), players can use other types of behavior, namely, altruistic, aggressive and paradoxical types Kleimenov [1997], Kleimenov and Kryazhimskii [1998].

These three types of behavior can be formalized as follows:

Definition 3. We say that Player 1 is confined in the current position of the game by *altruistic* (*alt*) type of behavior if his actions in this position are directed exclusively towards maximizing the functional I_2 (3) of Player 2.

Definition 4. We say that Player 1 is confined in the current position of the game by *aggressive* (*agg*) type of behavior if his actions in this position are directed exclusively towards minimizing the functional I_2 (3) of Player 2.

Definition 5. We will say that Player 1 is confined in the current position of the game by *paradoxical* (*par*) type of behavior if his actions in this position are directed exclusively towards minimizing own payoff I_1 (3).

Similarly, we define the altruistic and aggressive types of Player 2 behavior towards Player 1, as well as the paradoxical type of behavior for Player 2.

Note that the aggressive type of player behavior is actually used in NPDG in the form of punishment strategies contained in the structure of the game's decisions (see, for example, Kleimenov [1993], Kononenko [1976], Tolwinski et al [1986]).

The above definitions characterize the extreme types of behavior of players. In reality, however, real individuals behave, as a rule, partly normal, partly altruistic, partly aggressive and partly paradoxical. In other words, mixed types of behavior seem to be more consistent with reality. If each player is confined to "pure" types of behavior, then in the considered game of two persons with dynamics (1) and functionals I_i (3) there are 16 possible pairs of types of behavior: (*nor, nor*), (*nor, alt*), (*nor, agg*), (*nor, par*), (*alt, nor*), (*alt, alt*), (*alt, agg*), (*alt, par*), (*agg, nor*), (*agg, alt*), (*agg, agg*), (*agg, par*), (*par, nor*), (*par, alt*), (*par, agg*), (*par, par*). For the following four pairs (*nor, alt*), (*alt, nor*), (*agg, par*) and (*par, agg*) the interests of the players coincide and they solve a team problem of control. For the following four pairs (*nor, agg*), (*alt, par*), (*agg, nor*) and (*par, alt*) players have opposite interests and, therefore, they play an antagonistic differential game. The remaining 8 pairs define a non-antagonistic differential games.

The idea of using the players to switch their behavior from one type to another in the course of the game was applied to the game with cooperative dynamics in Kleimenov and Kryazhimskii [1998] and for the repeated bimatrix 2×2 game in Kleimenov [1999], which allowed to obtain new solutions in these games.

The extension of this approach to non-antagonistic positional differential games leads to new formulation of problems. In particular, it is of interest to see how the player's winnings, obtained on Nash solutions, are transformed. The actual task is to minimize the time of "abnormal" behavior, provided that the players' payoffs are greater than when the players behave normally.

Thus, we assume that players can switch from one type of behavior to another in the course of the game. Such a game will be called a non-antagonistic positional differential game with behavior types (NPDGwBT).

3.2 BT-solution in NPDGwBT.

In NPDGwBT we assume that simultaneously with the choice of positional strategy, each player also chooses his indicator function defined on the interval $t \in [t_0, \vartheta]$ and taking the value in the set $\{nor, alt, agg, par\}$. We denote the indicator function of Player i by the symbol $\alpha_i : [t_0, \vartheta] \rightarrow \{nor, alt, agg, par\}$, $i = 1, 2$. If the indicator function of some player takes a value, say, *alt* on some time interval, then this player acts on this interval as an altruist in relation to his partner. Note also that if the indicator functions of both players are identically equal to the value *nor* on the whole time interval of the game, then we have a classical NPDG.

Thus, in the game NPDGwBT Player 1 controls the choice of a pair of *actions* {position strategy, indicator function} $(U, \alpha_1(\cdot))$, and Player 2 controls the choice of a pair of actions $(V, \alpha_2(\cdot))$.

As mentioned above, for any pair of types of behavior three types of decision making problems can arise: a team problem, an antagonistic game, and a non-antagonistic game. We will assume that the players for each of these three problems are guided by the following Rules 1-2.

Rule 1. If on the time interval $(\tau_1, \tau_2) \subset [t_0, \vartheta]$ the player's indicator functions generate a non-antagonistic

game, then on this interval P1 and P2 choose one of $P(NE)$ - solutions of this game. If an antagonistic game is realized, then as a solution, P1 and P2 choose the saddle point of this game. Finally, if a team problem of control is realized, then P1 and P2 choose one of the pairs of controls such that the value function $\gamma_i(t, x)$ calculated along the generated trajectory is non-decreasing function, where i is the number of the player whose functional is maximized in team problem.

Generally speaking, the same part of the trajectory can be tracked by several pairs of players' types of behavior, and these pairs may differ from each other by the time of use of abnormal types. It is natural to introduce the following Rule 2.

Rule 2. If there are several pairs of types of behavior that track a certain part of the trajectory, then players choose one of them that minimizes the time of using abnormal types of behavior.

We now introduce the definition of the solution of the game NPDGwBT. Note that the set of motions generated by a pair of actions $\{(U, \alpha_1(\cdot)), (V, \alpha_2(\cdot))\}$ coincides with the set of motions generated by the pair (U, V) in the corresponding NPDG.

Definition 6. The pair $\{(U^0, \alpha_1^0(\cdot)), (V^0, \alpha_2^0(\cdot))\}$, consistent with Rule 1, forms a BT -solution of the game NPDGwBT if there exists a trajectory $x^{BT}(\cdot)$ generated by this pair and there is a $P(NE)$ -solution in the corresponding game NPDG generating the trajectory $x^P(\cdot)$ such that the following inequalities are true

$$\sigma_i(x^{BT}(\vartheta)) \geq \sigma_i(x^P(\vartheta)), \quad i = 1, 2, \quad (9)$$

where at least one of the inequalities is strict.

Definition 7. The BT -solution $\{(U^0, \alpha_1^0(\cdot)), (V^0, \alpha_2^0(\cdot))\}$, which is Pareto non-improvable with respect to the values I_1, I_2 (3), is called $P(BT)$ -solution of the game NPDGwBT.

Problem 1. Find the set of BT -solutions.

Problem 2. Find the set of $P(BT)$ -solutions.

In the general case, Problems 1 and 2 have no solutions. However, it is quite expected that the use of abnormal behavior types by players in the game NPDGwBT can in some cases lead to outcomes more preferable for them than in the corresponding game NPDG only with a normal type of behavior. An example of this kind is given in the next section.

4. EXAMPLE

Let equations of dynamics be as follows

$$\begin{aligned} \dot{x} &= u + v, \quad x, u, v \in R^2, \quad \|u\| \leq 1, \quad \|v\| \leq 1, \\ 0 &\leq t \leq \vartheta, \quad x(0) = x^0, \end{aligned} \quad (10)$$

where x is the phase vector; u and v are controls of P1 and P2, respectively. Let cost functional of Player i be

$$I_i = \sigma_i(x(\vartheta)) = 20 - \|x(\vartheta) - a^{(i)}\|, \quad i = 1, 2. \quad (11)$$

That is, the goal of Player i is to bring vector $x(\vartheta)$ as close as possible to the target point $a^{(i)}$.

Let the following initial conditions and values of parameters be given: $\vartheta = 5.0$, $x_0 = (0, 0)$, $a^{(1)} = (11, 9)$, $a^{(2)} = (-11, 9)$ (Fig. 1).

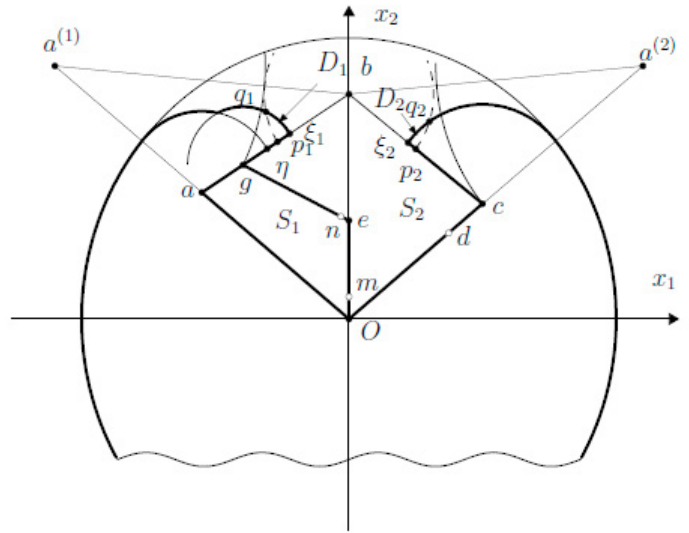


Fig. 1. Attainability set.

The game has the following phase restrictions. The trajectories of the system (10) are forbidden from entering the interior of the set S , which is obtained by removing from the quadrilateral $Oabc$ the two-link broken line Oeg . The set S consists of two parts S_1 and S_2 , that is, $S = S_1 \cup S_2$. Coordinates of the points defining the phase constraints: $a = (-5.5, 4.5)$, $b = (0, 8)$, $c = (5, 4.1)$, $O = (0, 0)$, $e = (0, 3.5)$, $g = (-3.96, 5.48)$. It can be verified that the point a lies on the interval $Oa^{(1)}$, and the point g lies on the interval ab . Note also that the point c lies just above the segment $Oa^{(2)}$.

Attainability set of the system (10) constructed for the moment ϑ consists of points of the circle of radius 10 located not higher than the three-link segment aOc and also bounded by two arcs connecting the large circle with the sides ab and bc of the quadrilateral. And the first (composite) arc consists of an arc of a circle with center at point a and radius $r_1 = |a\eta|$ and an arc of a circle with center at point g and radius $r = |g\xi_1|$. The second arc is an arc of the circle with center at the point c and radius $r_2 = |c\xi_2|$ (Fig. 1).

Results of approximate calculations: $r = 2.0726$, $r_1 = 2.8937$, $r_2 = 3.5335$, $\eta = (-3.0587, 6.0536)$, $\xi_1 = (-2.2114, 6.5927)$, $\xi_2 = (2.2135, 6.2735)$. In addition, we have: $|Oa^{(1)}| = |Oa^{(2)}| = 14.2127$ and $|a^{(1)}b| = |a^{(2)}b| = 11.0454$.

In Fig. 1 the dashed lines represent arcs of the circle L with center at the point b and radius $r_3 = 3.1673 = 14.2127 - 11.0454$. These arcs intersect the sides ab and bc at the points $p_1 = (-2.6721, 6.2995)$ and $p_2 = (2.4974, 6.0520)$, respectively. By construction, the lengths of the two-links $a^{(1)}bp_2$ and $a^{(2)}bp_1$ are equal to each other and equal to the lengths of the segments $Oa^{(1)}$ and $Oa^{(2)}$.

The value functions $\gamma_1(t, x)$ and $\gamma_2(t, x)$, $0 \leq t \leq \vartheta$, $x \in R^2 \setminus S$ (6) of the corresponding auxiliary antagonistic games Γ_1 and Γ_2 in this example will be as follows

$$\gamma_i(t, x) = \begin{cases} 20 - \|x - a^{(i)}\|, & xa^{(i)} \cap \text{int}S = \emptyset \\ 20 - \rho_S(x, a^{(i)}), & \text{otherwise} \end{cases}, \quad (12)$$

where $i = 1, 2$, and $\rho_S(x, a^{(i)})$ denotes the smallest of the two distances from the point x to the point $a^{(i)}$, one of which is calculated when the set S is bypassed clockwise and the other counterclockwise.

At first we solve the game NPDG (without abnormal behavior types). One can check that in the game NPDG the trajectory $x(t) \equiv 0$, $t \in [0, 5]$ (stationary point O) is a Nash trajectory. Further, the trajectories constructed along the broken line Oeg , are not Nash ones, since none of them is satisfied condition (8). This is also confirmed by the fact that the circle of radius $|a^{(1)}g|$ with the center at the point $a^{(1)}$ has no points in common with the circle L (see Fig. 1). Obviously, these are not Nash and all the trajectories that bypass the set S_2 on the right, since a circle of radius $|a^{(2)}c|$ with the center at the point $a^{(2)}$ also has no points in common with the circle L . Are not Nash and all trajectories that bypass the set S_1 on the left. As a result, it turns out that the mentioned trajectory $x(t) \equiv 0$, $t \in [0, 5]$ is the only Nash trajectory, and, consequently, the only $P(NE)$ -trajectory; the players' gains on it are $I_1 = I_2 = 5.7873$.

Let us now turn to the game NPDGwBT, in which each player during certain periods of time may exhibit altruism and aggression towards another player, and the case of mutual aggression is allowed.

We consider two variants of the game.

Variant I. We assume that P1 and P2 together with a normal type of behavior, can exhibit altruism towards their partner during some time intervals.

Variant II. In addition to the assumption of altruism of the players, we assume that each player can act aggressively against another player for some periods of time, and a case of mutual aggression is allowed.

In the attainability set, we find all the points x for which inequalities hold

$$\sigma_i(x) \geq \sigma_i(O), \quad i = 1, 2, \quad \sigma_1(x) + \sigma_2(x) > \sigma_1(O) + \sigma_2(O) \quad (13)$$

Such points form two sets D_1 and D_2 (see Fig. 1). The set D_1 is bounded by the segment $p_1\xi_1$, and also by the arcs p_1q_1 and $q_1\xi_1$ of the circles mentioned above. The set D_2 is bounded by the segment $p_2\xi_2$, and also by the arcs ξ_2q_2 and q_2p_2 of the circles mentioned. On the arc p_1q_1 , the non-strict inequality (8) for $i = 2$ becomes an equality, and on the arc q_2p_2 , the non-strict inequality (8) becomes an equality for $i = 1$. At the remaining points sets D_1 and D_2 , the non-strict inequalities (8) for $i \in \{1, 2\}$ are strict.

Now within the framework of variant I we construct a BT -solution leading to the point $\xi_2 \in D_2$. Consider the trajectory $Oc\xi_2$; the players' payoffs on it are $I_1 = 6.1474$, $I_2 = 10.8002$, that is, each player gets payoff which is greater than on single $P(NE)$ -trajectory. How follows from the foregoing, the trajectory $Oc\xi_2$ is not Nash one. However, if it is possible to construct indicator functions-programs of players that provide motion along this trajectory, then a BT -solution will be constructed.

On the side Oc , we find a point d equidistant from the point $a^{(1)}$ if we go around the set S clockwise, or if we go around S counterclockwise. We obtain $d = (3.7271, 3.0562)$. Further, if we move along the trajectory

$Oc\xi_2$ with the maximum velocity for $t \in [0, 5]$, then the time to hit the point d will be $t = 2.4100$, and for the point c will be $t = 3.2330$. It can be verified that if we move along this trajectory on the time interval $[0, 2.4100]$ then the function $\gamma_1(t, x)$ (12) decreases monotonically and the function $\gamma_2(t, x)$ (12) increases monotonically; for motion on the interval $t \in [2.4100, 3.2330]$, both functions $\gamma_1(t, x)$ and $\gamma_2(t, x)$ increase monotonically; finally, when driving on the remaining interval $t \in [3.2330, 5.0]$, then the function $\gamma_1(t, x)$ increases monotonically, and the function $\gamma_2(t, x)$ decreases.

We check that on the segment Od of the trajectory the pair (alt, nor) , which defines a team problem of control, is the only pair of types of behavior that realizes motion on this segment in accordance with Rule 1; this is the maximum shift in the direction of the point $a^{(2)}$. In the next segment dc there will already be four pairs of "candidates" (nor, nor) , (alt, nor) , (nor, alt) and (alt, alt) , but according to Rule 2 the last three pairs are discarded; the remaining pair determines a non-antagonistic game, and the motion on this segment will be generated by $P(NE)$ -solution of the game. Finally, for the last segment $c\xi_2$, the only pair of types of behavior, that generates motion on the segment in accordance with Rule 1, there will be a pair (nor, alt) that defines a team problem of control; the motion represents the maximum shift in the direction of the point ξ_2 .

Thus, we have constructed the following indicator function-programs of players

$$\alpha_1^{(1)}(t) = \{alt, t \in [0, 2.4100]; \quad nor, t \in [2.4100, 5]\}, \quad (14)$$

$$\alpha_2^{(1)}(t) = \{nor, t \in [0, 3.2330]; \quad alt, t \in [3.2330, 5]\}. \quad (15)$$

We denote by $(U^{(1)}, V^{(1)})$ the pair of players' strategies that generates the limit motion $Oc\xi_2$ for $t \in [0, 5]$ and is consistent with the constructed indicator functions. Then we obtain the following assertion.

Theorem 1. In variant I, the pair of actions $\{(U^{(1)}, \alpha_1^{(1)}(\cdot)), (V^{(1)}, \alpha_2^{(1)}(\cdot))\}$ (14), (15) provides the $P(BT)$ -solution.

We turn to the variant II, in which, in addition to assuming the altruism of the players, it assumed that players can use an aggressive type of behavior. We construct a BT -solution, leading to the point $\xi_1 \in D_1$.

Let us find the point m equidistant from the point $a^{(1)}$ if we go around the set S_1 clockwise, or if we go around S_1 counterclockwise. We also find a point n equidistant from the point $a^{(2)}$ as if we were go around the set S_2 clockwise, or if we go around S_2 counterclockwise. The results of the calculations: $m = (0, 0.7928)$, $n = (-0.2925, 3.6462)$.

Consider the trajectory $Oeg\xi_1$; the players' payoffs on it are $I_1 = 10.8840$, $I_2 = 6.5359$, that is, the payoffs of both players on this trajectory are greater than payoffs on the single $P(NE)$ -trajectory. As follows from the above, the trajectory $Oeg\xi_1$ is not Nash one. Therefore, if it is possible to construct indicator functions-programs of players that provide motion along this trajectory, then a BT -solution will be constructed.

First of all find that if we move along the trajectory $Oeg\xi_1$ with the maximum velocity for $t \in [0, 5]$, the time to hit the point m will be $t = 0.3964$, the point n will be $t = 1.9135$, and the point g will be $t = 3.9620$. It is easy to verify that for such a motion along the trajectory $Oeg\xi_1$ on the interval $t \in [0, 0.3964]$, both functions $\gamma_1(t, x)$ and $\gamma_2(t, x)$ (12) decrease monotonically; for motion on the interval $t \in [0.3964, 1.9135]$, the function $\gamma_2(t, x)$ continues to decrease, and the function $\gamma_1(t, x)$ increases; for motion on the interval $t \in [1.9135, 3.9620]$, both functions increase; finally, on the remaining interval $t \in [3.9620, 5]$, the function $\gamma_2(t, x)$ continues to increase, and the function $\gamma_1(t, x)$ decreases.

We check that on the segment Om of the trajectory, the pair (agg, agg) , which determines the non-antagonistic game, is the only pair of types of behaviors that realizes motion on the segment in accordance with Rule 1; this is the motion generated by the $P(NE)$ -solution, the best for both players.

In the next segment mn , two pairs of types of behaviors realize motion on the segment according to Rule 1, namely (nor, alt) and (agg, alt) ; however, according to Rule 2, only the pair (nor, alt) remains; it defines a team problem of control in which the motion represents the maximum shift in the direction of point n .

There are already four pairs of "candidates" (nor, nor) , (alt, nor) , (nor, alt) and (alt, alt) on the segment ng , but according to Rule 2 the last three pairs are discarded; the remaining pair defines a non-antagonistic game and the motion on this segment is generated by the $P(NE)$ -solution of the game.

Finally, for the last segment $g\xi_1$, the only pair of types of behaviors is the pair (alt, nor) , which defines a team problem of control; the motion represents the maximum shift in the direction of the point ξ_1 .

Thus, we have constructed the following indicator function-programs of players

$$\alpha_1^{(2)}(t) = \{agg, t \in [0, 0.3964]; \quad nor, t \in [0.3964, 3.9620]; \},$$

$$\alpha_1^{(2)}(t) = \{alt, t \in [3.9620, 5]\}, \quad (16)$$

$$\alpha_2^{(2)}(t) = \{agg, t \in [0, 0.3964]; \quad alt, t \in [0.3964, 1.9135]; \}.$$

$$\alpha_2^{(2)}(t) = \{nor, t \in [1.9135, 5]\}. \quad (17)$$

We denote by $(U^{(2)}, V^{(2)})$ the pair of players' strategies that generate the limit motion $Oeg\xi_1$ for $t \in [0, 5]$ and is consistent with the constructed indicator functions. Then we obtain the following assertion.

Theorem 2. In variant II, the pair of actions $\{(U^{(2)}, \alpha_1^{(2)}(\cdot)), (V^{(2)}, \alpha_2^{(2)}(\cdot))\}$ (16), (17) provides the $P(BT)$ -solution.

Remark 1. It is obvious that Theorem 1 is also true for variant II.

Following the scheme of the proofs of Theorems 1 and 2 (and also taking into account Remark 1), we arrive at the following Theorems.

Theorem 3. In variant I, the set D_2 consists of those and only those points that are endpoints of the trajectories generated by the BT -solutions of the game.

Theorem 4. In variant II, the sets D_1 and D_2 consist of those and only those points that are the ends of the trajectories generated by the BT -solutions of the game.

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